

In the Claims:

Please amend the claims as follows:

1. (currently amended) A wrist unit (~~6~~), intended to be connected to a robot arm in an industrial robot, ~~wherein~~ the wrist unit ~~comprises~~ comprising:

a wrist housing (~~7~~),

a wrist part/tilt (~~8, 33~~) pivotally journalled in the wrist housing (~~7~~) for rotation about a fifth axis of rotation (~~E~~), and

a turn disc (~~9~~) rotatably journalled in the wrist part/the tilt (~~8, 33~~) for rotation about a sixth axis of rotation (~~F~~), wherein the sixth axis of rotation (~~F~~) is configured to cross the fifth axis of rotation (~~E~~), ~~the wrist housing (~~7~~) further comprising~~

a first transmission (~~10~~) configured to transmit rotation about the fifth axis of rotation (~~E~~) to the wrist part/the tilt (~~8, 33~~), and

a second transmission (~~11~~) configured to transmit rotation about the sixth axis of rotation (~~F~~) to the turn disc (~~9~~), ~~characterized in that~~ wherein the second transmission (~~11~~) comprises a drive-shaft tube arranged symmetrically along the symmetry axis (~~G~~) of the wrist housing, the drive-shaft tube (~~12~~) is configured to form a continuous channel (~~14~~), the channel (~~14~~) is configured to receive and accommodate continuous cabling.

2. (currently amended) A The wrist unit according to claim 1, ~~wherein~~ further comprising:

at least one drive means (~~30, 31~~) is arranged for driving one of the transmission (~~10, 11~~).

3. (currently amended) A robot arm comprising a module in the form of a wrist unit according to claim 1 ~~or~~ 2.

4. (currently amended) A The wrist unit according to ~~any of the preceding claims~~ claim 1, wherein the wrist part/the tilt (8) is journalled in double-sided bearings.

5. (currently amended) A The wrist unit according to ~~any of claims 1-3~~ claim 1, wherein the wrist part/the tilt (33) is journalled in a single-sided bearing.

6. (currently amended) An industrial robot, comprising:
a control system and
a manipulator ~~which includes~~ comprising a robot arm (5) and a wrist unit (6), arranged on the robot arm, ~~according to claim 1~~, said wrist unit comprising a wrist housing (7) arranged for rotation about a fourth axis of rotation (D), a wrist part/tilt (8, 33) pivotally journalled in the wrist housing (7) for rotation about a fifth axis of rotation (E), and a turn disc (9) rotatably journalled in the wrist part/the tilt (8, 33) for rotation about a sixth axis of rotation (F), wherein the sixth axis of rotation (F) is configured to intersect the fifth axis of rotation (E), the wrist housing (7) further comprising a first transmission (10) configured to transmit rotation from a first drive means (30) to the tilt (8, 33) for rotation about the fifth axis of rotation (E), and a second transmission (11) configured to transmit rotation from a second drive means (31) to the turn disc (9) for rotation about the sixth axis of rotation (F), ~~characterized in that~~ wherein the first transmission (11) comprises a drive-shaft tube (12) arranged symmetrically along the fourth axis

of rotation (~~D~~), the drive-shaft tube (~~12~~) is configured to form a continuous channel (~~14~~), and ~~that~~ wherein cabling (~~29~~) is arranged drawn through the channel (~~14~~), through the wrist part/the tilt (~~8, 33~~) and is secured to the turn disc that at least one section of the cabling (~~14a~~) is radially fixed to the second drive-shaft tube (~~12~~).

7. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the robot arm comprises at least one drive means (~~30, 31~~).

8. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the drive means (~~30, 31~~) are arranged inside the robot arm (~~5~~).

9. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the drive means (~~30, 31~~) are arranged on the robot arm (~~5~~).

10. (currently amended) ~~An~~ The industrial robot according to claim 6, wherein the wrist unit (~~6~~) comprises at least one drive means (~~30, 31~~).

11. (currently amended) A method in an industrial robot (~~1~~) with a control system and a manipulator comprising a robot arm (~~5~~) and a wrist unit (~~6~~), arranged on the robot arm, said wrist unit comprising a wrist housing (~~7~~) arranged for rotation about a fourth axis of rotation (~~D~~), a wrist part/tilt (~~8, 33~~) pivotally journalled in the wrist housing (~~7~~) for rotation about a fifth axis of rotation (~~E~~), and a turn disc (~~9~~) rotatably journalled on the wrist part/the tilt (~~8, 33~~) for rotation about a sixth axis of rotation (~~F~~), wherein the sixth axis of rotation (~~F~~) is configured to cross the

fifth axis of rotation (E), the wrist housing (7) further comprising a first transmission (10) configured to transmit rotation from a first drive means (30) to the tilt (8) for rotation about the fifth axis of rotation (E), and a second transmission (11) configured to transmit rotation from a second drive means (31) to the turn disc (9) for rotation about the sixth axis of rotation (F), wherein the control system Θ controls the first (30) and second (31) drive units, ~~characterized in that~~ the method comprising:

bringing the control system ~~is brought~~ to control the first (30) and second drive units such that the gear ratio between a drive-shaft tube included in the first transmission (10), and the turn disc (9) is 1:1.